Amendments to the Claims:

This listing of claims replaces all prior versions and listings of claims in the application:

Listing of Claims:

1. (Previously presented) A system for tracking the motion of an object relative to a moving reference frame, comprising:

a first inertial sensor mounted on the tracked object;

a second inertial sensor mounted on the moving reference frame;

a third inertial sensor mounted on the moving reference frame and spaced apart from the second inertial sensor; and

an element coupled to said first and second and third inertial sensors and configured to determine a position of the object relative to the moving reference frame based on the signals from the first and second and third inertial sensors, wherein the determination of the position of the object includes determination of at least one component of an angular acceleration of the moving reference frame and wherein the determination of the angular acceleration is made by combining linear acceleration data from the second and third inertial sensors.

2. (Canceled)

3. (Canceled)

4. (Previously presented) The system of claim 1, further comprising a non-inertial measuring subsystem for making independent measurements related to the position of the object relative to the moving reference frame, and a drift corrector using them said independent measurements for correcting to correct any drift that may occur in the an inertial orientation integration.

5. (Original) The system of claim 4, in which the non-inertial measuring subsystem is selected from the set of optical, acoustic, magnetic, RF, or electromagnetic technologies.

6. (Original) The system of claim 5, in which the non-inertial measuring system is optical and involves measurement of the location of one or more targets in the image planes of one or more sensors.

7. (Previously presented) The system of claim 6, where the targets emit radiation within a defined bandwidth about a central wavelength selected in the infrared, visible or ultraviolet region of the an electromagnetic spectrum.

8. (Original) The system of claim 7, where the central wavelength is substantially invisible to night vision equipment.

9. (Previously presented) The system of claim 7, where the central wavelength is substantially invisible to the a human eye.

10. (Original) The system of claim 6, in which at least one optical sensor is mounted on the tracked object.

11. (Original) The system of claim 10, further comprising at least one optical sensor mounted rigidly with respect to the moving reference frame.

12. (Original) The system of claim 6, in which the optical system comprises two sensors mounted rigidly with respect to the moving reference frame, and separated by at least 10 centimeters.

13. (Original) The system of claim 12, in which the second inertial sensor is physically packaged with one of the optical sensors, and the third inertial sensor is physically packaged with the other optical sensor.

14. (Previously presented) A system for tracking the motion of an object relative to a moving reference frame comprising:

a first inertial sensor mounted on the tracked object;

a second inertial sensor mounted on the moving reference frame;

a third inertial sensor mounted on the moving reference frame and spaced apart from the second inertial sensor;

an element coupled to said first and second and third inertial sensors and configured to determine a position of the object relative to the moving reference frame based on the signals from the first and second and third inertial sensors; and

a drift corrector for correcting inertial drift in the determined orientation position of the object with respect to the moving reference frame,

wherein the determination of the position of the object includes determination of at least one component of an angular acceleration of the moving reference frame and wherein the determination of the angular acceleration is made by combining linear acceleration data from the second and third inertial sensors.

15. (Original) The system of claim 14, where the drift corrector includes a Kalman filter.

16. (Previously presented) A system for tracking the motion of an object relative to a moving reference frame comprising:

a first inertial sensor mounted on the tracked object;

a second inertial sensor mounted on the moving reference frame;

means coupled to said first and second inertial sensors for determining an orientation of the object relative to the moving reference frame based on the signals from the first and second inertial sensors; and

a drift corrector for correcting inertial drift in the determined orientation of the object with respect to the moving reference frame, where the drift corrector includes a Kalman filter.

17. (Previously presented) A method for tracking the motion of an object relative to a moving reference frame comprising:

mounting a first inertial sensor on the tracked object;

mounting a second inertial sensor on the moving reference frame;

determining an orientation of the object relative to the moving reference frame based on the signals from the first and second inertial sensors; and

correcting inertial drift in the determined orientation of the object with respect to the moving reference frame, using a Kalman filter.

18. (Original) The system of claim 15, 16, or 17, where the Kalman filter is configured to estimate biases of both the first and second inertial sensors, which become separately observable over time as the tracked object changes orientation relative to the moving reference frame.

19. (Previously presented) A system for tracking the motion of an object relative to a moving reference frame comprising:

a tracking inertial measurement unit mounted on the tracked object;

three reference inertial measurement units mounted at three separated and non-collinear locations on the moving reference frame;

an element coupled to said tracking inertial measurement unit and to said reference inertial measurement units and configured to determine an orientation and a position of the object relative to the moving reference frame based on the signals from the inertial measurement units; and

an element coupled to said reference inertial measurement units and configured to determine the an angular acceleration of the moving reference frame based on the signals from the inertial measurement units.

20. (Original) The system of claim 19 where the determination of angular acceleration of the moving reference frame involves analysis of the differences of linear accelerations measured between each pair of separated reference inertial measurement units.

21. (Previously presented) A system for tracking the motion of an object relative to a reference frame, comprising:

an optical sensor for measuring the a location of a target in an image plane;

at least three light-emitting targets which emit invisible ultraviolet radiation which can be detected by the optical sensor but which does not interfere with night vision equipment;

an element coupled to said optical sensor and configured to determine a position of the object relative to the reference frame based on the locations of the ultraviolet targets in the image plane of the optical sensor(s).

22. (Previously presented) A system for tracking the motion of an object relative to a moving reference frame, comprising:

a first inertial sensor mounted on the tracked object;

a second inertial sensor mounted on the moving reference frame;

a third inertial sensor mounted on the moving reference frame and spaced apart from the second inertial sensor;

an element coupled to said first and second and third inertial sensors and configured to determine a position of the object relative to the moving reference frame based on signals from the first and second and third inertial sensors, and

an optical measuring subsystem for making independent measurements related to the position of the object relative to the moving reference frame by measuring the location of one or more targets in the image planes of one or more sensors.

23. (Previously presented) The system of claim 22, wherein the targets emit radiation within a defined bandwidth about a central wavelength selected in the infrared, visible or ultraviolet region of the electromagnetic spectrum.

24. (Previously presented) The system of claim 23, wherein the central wavelength is substantially invisible to night vision equipment.

25. (Previously presented) The system of claim 23, wherein the central wavelength is substantially invisible to the human eye.

26. (New) A method for tracking the motion of an object relative to a moving reference frame, comprising:

mounting a first inertial sensor on the tracked object;

mounting a second inertial sensor on the moving reference frame;

mounting a third inertial sensor mounted on the moving reference frame, spaced apart from the second inertial sensor; and

coupling an element to said first and second and third inertial sensors, said element being configured to determine a position of the object relative to the moving reference frame based on the signals from the first and second and third inertial sensors, wherein the determination of the position of the object includes determination of at least one component of an angular acceleration of the moving reference frame and wherein the determination of the angular acceleration is made by combining linear acceleration data from the second and third inertial sensors.

27. (New) The method of claim 26, further comprising providing a non-inertial measuring subsystem for making independent measurements related to the position of the object relative to the moving reference frame and using a drift corrector to correct drift that may occur in an inertial orientation integration, using said independent measurements.

28. (New) The method of claim 27, wherein the non-inertial measuring subsystem is selected from the set of optical, acoustic, magnetic, RF, or electromagnetic technologies.

29. (New) The method of claim 28, in which the non-inertial measuring system is optical and measures the location of one or more targets in the image planes of one or more sensors.

30. (New) The method of claim 29, where the targets emit radiation within a defined bandwidth about a central wavelength selected in the infrared, visible or ultraviolet region of an electromagnetic spectrum.

31. (New) The method of claim 30, where the central wavelength is substantially invisible to night vision equipment.

32. (New) The method of claim 30, where the central wavelength is substantially invisible to a human eye.

33. (New) The method of claim 29, in which at least one optical sensor is mounted on the tracked object.

34. (New) The method of claim 33, further comprising mounting at least one optical sensor rigidly with respect to the moving reference frame.

35. (New) The method of claim 29, in which the optical system comprises two sensors mounted rigidly with respect to the moving reference frame, and separated by at least 10 centimeters.

36. (New) The method of claim 35, in which the second inertial sensor is physically packaged with one of the optical sensors, and the third inertial sensor is physically packaged with the other optical sensor.

37. (New) A method for tracking the motion of an object relative to a moving reference frame comprising:

mounting a first inertial sensor on the tracked object;

mounting a second inertial sensor mounted on the moving reference frame;

mounting a third inertial sensor on the moving reference frame and spacing it apart from the second inertial sensor;

coupling an element to said first and second and third inertial sensors, said element configured to determine a position of the object relative to the moving reference frame based on signals from the first and second and third inertial sensors; and

using a drift corrector to correct inertial drift in a determined orientation of the object with respect to the moving reference frame,

wherein the determination of the position of the object includes determination of at least one component of an angular acceleration of the moving reference frame and wherein the

determination of the angular acceleration is made by combining linear acceleration data from the second and third inertial sensors.

38. (New) The method of claim 37, where the drift corrector includes a Kalman filter.

39. (New) A method for tracking the motion of an object relative to a moving reference frame comprising:

mounting a first inertial sensor on the tracked object;

mounting a second inertial sensor on the moving reference frame;

coupling to said first and second inertial sensors a device for determining an orientation of the object relative to the moving reference frame based on signals from the first and second inertial sensors; and

using a drift corrector to correct inertial drift in the determined orientation of the object with respect to the moving reference frame, where the drift corrector includes a Kalman filter.

40. (New) The method of claim 39, further comprising using the Kalman filter to estimate biases of both the first and second inertial sensors, which become separately observable over time as the tracked object changes orientation relative to the moving reference frame.

41. (New) A method for tracking the motion of an object relative to a moving reference frame comprising:

mounting a tracking inertial measurement unit on the tracked object;

mounting three reference inertial measurement units mounted at three separated and non-collinear locations on the moving reference frame;

coupling an element to said tracking inertial measurement unit and to said reference inertial measurement units and, said element being configured to determine an orientation and a position of the object relative to the moving reference frame based on signals from the inertial measurement units; and

coupling an element to said reference inertial measurement units, said element configured to determine an angular acceleration of the moving reference frame based on the signals from the inertial measurement units.

42. (New) The method of claim 41 where the determination of angular acceleration of the moving reference frame involves analysis of the differences of linear accelerations measured between each pair of separated reference inertial measurement units.

43. (New) A method for tracking the motion of an object relative to a reference frame, comprising:

providing an optical sensor for measuring a location of a target in an image plane;

providing at least three light-emitting targets which emit invisible ultraviolet radiation which can be detected by the optical sensor but which does not interfere with night vision equipment;

coupling an element to said optical sensor, said element configured to determine a position of the object relative to the reference frame based on locations of the ultraviolet targets in the image plane of the optical sensor.

44. (New) A method for tracking the motion of an object relative to a moving reference frame, comprising:

mouting a first inertial sensor on the tracked object;

mounting a second inertial sensor on the moving reference frame;

mounting a third inertial sensor on the moving reference frame and spacing it apart from the second inertial sensor;

coupling an element to said first and second and third inertial sensors, said element being configured to determine a position of the object relative to the moving reference frame based on signals from the first and second and third inertial sensors, and

using an optical measuring subsystem to make independent measurements related to the position of the object relative to the moving reference frame by measuring the location of one or more targets in the image planes of one or more sensors.

45. (New) The method of claim 44, wherein the targets emit radiation within a defined bandwidth about a central wavelength selected in the infrared, visible or ultraviolet region of the electromagnetic spectrum.

46. (New) The method of claim 45, wherein the central wavelength is substantially invisible to night vision equipment.

47. (New) The method of claim 45, wherein the central wavelength is substantially invisible to the human eye.